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Abstract

A positioning system eg for a robot includes a position command portion 1A which outputs a position command value for a controlled object 3, and a position control portion (2) which controls the controlled object so that its actual position value agrees with the position command value. The apparatus further includes a mass estimation portion 4 which estimates the mass or inertia value of the controlled object 4, a maximum acceleration computing portion 4A which computes the maximum, achievable acceleration * small Greek alpha *max of the controlled object on the basis of the mass estimated by the mass estimation portion 4, and an acceleration limiter 11 which limits the second-order derivative of the position command value within the maximum acceleration * small Greek alpha *max . The positioning system can eliminate unstable operation which may be involved in setting parameters of the position command portion or the position control portion.

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